

3124605

Ref #	Hits	Search Query	DBs	Default Operator	Plurals	Time Stamp
L1	7	void same map\$4 same robot and model\$3	US-PGPUB; USPAT	OR	ON	2005/03/24 19:54
L2	4	("4884847" "6009359" "6405798" "6446718").pn.	US-PGPUB; USPAT	OR	ON	2005/03/24 20:06
L3	23	(void\$3 or hollow or tank or bunker\$3 or pipe or tunnel or cave or mine\$3) same map\$4 same robot and model\$3	US-PGPUB; USPAT	OR	ON	2005/03/24 19:51
L4	11	(pipe or tunnel or cave or mine\$3) same map\$4 same robot and model\$3	US-PGPUB; USPAT	OR	ON	2005/03/24 19:51
L5	11	(pipe or tunnel or cave or mine\$3) same map\$4 same robot and model\$3	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2005/03/24 19:52
L6	450	(pipe or tunnel or cave or mine\$3) same (bot or robot) and model\$3	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2005/03/24 19:53
L7	0	(pipe or tunnel or cave or mine\$3) same (bot or robot) and model\$3 and void same map\$4	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2005/03/24 19:53
L8	5	(pipe or tunnel or cave or mine\$3) same (bot or robot) and model\$3 and void and map\$4	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2005/03/24 19:53
L9	0	void same map\$4 same robot and mine\$3	US-PGPUB; USPAT	OR	ON	2005/03/24 19:55
L10	1	void and map\$4 same robot and mine\$3	US-PGPUB; USPAT	OR	ON	2005/03/24 19:55
L11	1	void and map\$4 same robot and mine\$3	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2005/03/24 19:56

L12	82	map\$4 same robot and mine\$3	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2005/03/24 19:57
L13	943	pipeline same pig	US-PGPUB; USPAT	OR	ON	2005/03/24 19:57
L14	33	("4884847" "6009359" "6405798" "6446718")	US-PGPUB; USPAT	OR	ON	2005/03/24 19:59
L15	33	("4884847" "6009359" "6405798" "6446718")	US-PGPUB; USPAT	OR	ON	2005/03/24 20:12
L18	6	tunnel same (bot or robot) same vehicle and map\$4	US-PGPUB; USPAT	OR	ON	2005/03/24 20:15
L19	0	tunnel same (bot or robot) same (truck or cart or vehicle) with tire\$3 and map\$4	US-PGPUB; USPAT	OR	ON	2005/03/24 20:16
L20	0	tunnel same (bot or robot) and (truck or cart or vehicle) with (tyre or tire) and map\$4	US-PGPUB; USPAT	OR	ON	2005/03/24 20:16
L21	26	tunnel and (bot or robot) and (truck or cart or vehicle) with (tyre or tire) and map\$4	US-PGPUB; USPAT	OR	ON	2005/03/24 20:17
L22	26	tunnel and (bot or robot) and (truck or cart or vehicle) with (tyre or tire) and map\$4	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2005/03/24 20:42
L23	267122	mine\$4	US-PGPUB; USPAT	OR	ON	2005/03/24 20:43
L24	11	mine\$4 and (robotic\$3 same map\$4 same mine\$3) or (mine\$3 same map\$4 same robot)	US-PGPUB; USPAT	OR	ON	2005/03/24 20:46
L25	110	mine\$4 and (robotic\$3 same map\$4) or (map\$4 same robot) and tunnel	US-PGPUB; USPAT	OR	ON	2005/03/24 20:48
L26	100	mine\$4 and (robotic\$3 same map\$4) or (map\$4 same robot) and tunnel and image	US-PGPUB; USPAT	OR	ON	2005/03/24 20:48
L27	81	mine\$4 and (robotic\$3 same map\$4) or (map\$4 same robot) and tunnel and image and interior	US-PGPUB; USPAT	OR	ON	2005/03/24 20:48
L28	81	mine\$4 and (robotic\$3 same map\$4) or (map\$4 same robot) and tunnel and image and interior and tunnel	US-PGPUB; USPAT	OR	ON	2005/03/24 20:48

L30	80	mine\$4 and (robotic\$3 same map\$4) or (map\$4 same robot) and tunnel and image and interior and tunnel and vehicle	US-PGPUB; USPAT	OR	ON	2005/03/24 20:49
L31	72	mine\$4 and (robotic\$3 same map\$4) or (map\$4 same robot) and tunnel and image and interior and tunnel and vehicle and lazer and range and finder	US-PGPUB; USPAT	OR	ON	2005/03/24 20:50
L32	72	mine\$4 and (robotic\$3 same map\$4) or (map\$4 same robot) and tunnel and image and interior and tunnel and vehicle and lazer and range and finder and interior and mine	US-PGPUB; USPAT	OR	ON	2005/03/24 20:51
L33	72	mine\$4 and (robotic\$3 same map\$4) or (map\$4 same robot) and tunnel and image and interior and tunnel and vehicle and lazer and range and finder and interior same mine	US-PGPUB; USPAT	OR	ON	2005/03/24 20:51
L34	72	mine\$4 and (robotic\$3 same map\$4) or (map\$4 same robot) and tunnel and image and interior and tunnel and vehicle and lazer and range and finder and interior same mine and (tire or tyre)	US-PGPUB; USPAT	OR	ON	2005/03/24 20:51
L35	72	mine\$4 and (robotic\$3 same map\$4) or (map\$4 same robot) and tunnel and image and interior and tunnel and vehicle and lazer and range and finder and interior same mine and (tire or tyre)	US-PGPUB; USPAT	OR	ON	2005/03/24 20:52
L36	72	mine\$4 and (robotic\$3 same map\$4) or (map\$4 same robot) and tunnel and image and interior and tunnel and vehicle and lazer and range and finder and interior same mine and (tire or tyre)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2005/03/24 20:52
L37	9	("4023861"   "4790402"   "4884847"   "5155684"   "5155775"   "5274437"   "5493499"   "5530330"   "5999865").PN.	US-PGPUB; USPAT; USOCR	OR	ON	2005/03/24 21:16
L38	1	("4023861"   "4790402"   "4884847"   "5155684"   "5155775"   "5274437"   "5493499"   "5530330"   "5999865").PN. and mine and tunnel	US-PGPUB; USPAT; USOCR	OR	ON	2005/03/24 21:16

L39	18	("4023861"   "4790402"   "4884847"   "5155684"   "5155775"   "5274437"   "5493499"   "5530330"   "5999865").PN.	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2005/03/24 21:24
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	U	1	Document ID	Issue Date	Pages
1	X		US 5999865 A	19991207	8
2	X		US 5530330 A	19960625	5
3	X		US 5493499 A	19960220	9
4	X		US 5274437 A	19931228	9
5	X		US 5155775 A	19921013	7
6	X		US 5155684 A	19921013	25
7	X	X	US 4884847 A	19891205	8
8	X		US 4790402 A	19881213	14
9	X		US 4023861 A	19770517	12
10	X		US 5999865 A	19991207	8
11	X		AU 9516167 A	19951012	5
12	X		DE 4222333 A	19930114	9

	Title	Current OR	Current XRef
1	Autonomous vehicle guidance system	701/25	299/1.05; 318/580; 701/200; 701/209; 701/23
2	Automated guidance system for a vehicle	318/580	180/116; 318/587
3	Method for determining the deviations of the actual position of a track section	701/207	342/357.08; 73/146
4	Apparatus and procedure for measuring the cross-section of a hollow space	356/606	
5	Structured illumination autonomous machine vision system	382/153	382/285; 701/28
6	Guiding an unmanned vehicle by reference to overhead features	701/25	318/587; 382/153; 701/205; 701/28
7	Apparatus and method for mapping entry conditions in remote mining systems	299/1.05	175/40; 299/30; 340/853.6
8	Automated guided vehicle	180/169	318/587; 348/119; 356/139.07; 356/141.1; 701/25
9	Method and apparatus for controlling a tunneling machine	299/1.8	299/75
10	Control system for guiding underground mine vehicles		
11	Automated vehicle guidance system for mine navigation - has vehicle with light source above vehicle and cameras connected to processor to control steering of vehicle		
12	Measuring deviation of actual position of rail section - measuring change in relative positions of measurement units starting from fixed positions and using satellite positioning		

	Image Doc. Displayed	PT
1	US 5999865	
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8	US 4790402	
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11	US 5530330	
12	US 5493499	

	U	1	Document ID	Issue Date	Pages
13	X		US 5155775 A	19921013	7
14	X		EP 501947 A	19920902	9
15	X		EP 366350 A	19900502	25
16	X		US 4884847 A	19891205	8
17	X		US 4790402 A	19881213	14
18	X		DE 2458514 A	19760616	12



	<b>Title</b>	<b>Current OR</b>	<b>Current XRef</b>
<b>13</b>	Structured illumination autonomous machine vision - automatically determining pathway boundaries for autonomous robotic navigation by viewing reflected light pattern with video camera		
<b>14</b>	Hollow chamber cross=section measurement for tunnel - using light plane and recording reflections at walls of chamber with vertical reference point and distance meter using camera		
<b>15</b>	Automatic unmanned guided vehicle - has observed overhead lights progressively recorded in on-board computer memory		
<b>16</b>	Mapping method for mine excavation and tunnel entry condition - using array of sensors on remotely controlled vehicle to provide information to generate map to be compared with previous maps		
<b>17</b>	Unmanned, self-propelled guided vehicle - has laser scanner which controls vehicle steering between programmed turns so vertical plane of scanner is always aligned with target		
<b>18</b>	Mine heading machine with laser beam guide - computer provides tool path limits and checks for tool position to prevent course deviation		

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13	US 5155775	
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15	US 5155684	
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18	US 4023861	

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8			US 4790402 A	19881213	14
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<b>2</b>	Automated guidance system for a vehicle	318/580	180/116; 318/587
<b>3</b>	Method for determining the deviations of the actual position of a track section	701/207	342/357.08; 73/146
<b>4</b>	Apparatus and procedure for measuring the cross-section of a hollow space	356/606	
<b>5</b>	Structured illumination autonomous machine vision system	382/153	382/285; 701/28
<b>6</b>	Guiding an unmanned vehicle by reference to overhead features	701/25	318/587; 382/153; 701/205; 701/28
<b>7</b>	Apparatus and method for mapping entry conditions in remote mining systems	299/1.05	175/40; 299/30; 340/853.6
<b>8</b>	Automated guided vehicle	180/169	318/587; 348/119; 356/139.07; 356/141.1; 701/25
<b>9</b>	Method and apparatus for controlling a tunneling machine	299/1.8	299/75

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7	US 4884847	
8	US 4790402	
9	US 4023861	

Ref #	Hits	Search Query	DBs	Default Operator	Plurals	Time Stamp
L1	7	void same map\$4 same robot and model\$3	US-PGPUB; USPAT	OR	ON	2005/03/24 18:36

	<b>Image Doc. Displayed</b>	<b>PT</b>
<b>1</b>	US 20020156551	
<b>2</b>	US 6629087	
<b>3</b>	US 6615111	
<b>4</b>	US 6604090	
<b>5</b>	US 6532401	
<b>6</b>	US 6363301	
<b>7</b>	US 6259969	

Search

	Title	Current OR	Current XRef
1	Methods for automatically focusing the attention of a virtual robot interacting with users	700/245	
2	Methods for creating and editing topics for virtual robots conversing in natural language	706/11	704/2; 715/841
3	Methods for automatically focusing the attention of a virtual robot interacting with users	700/246	704/9; 706/11
4	System and method for selecting responses to user input in an automated interface program	706/11	707/5; 715/856; 715/978
5	Methods for automatically verifying the performance of a virtual robot	700/245	318/568.1; 318/568.14; 700/264; 700/88; 701/200; 701/208; 701/29; 706/924; 710/104; 710/105; 710/266
6	System and method for automatically focusing the attention of a virtual robot interacting with users	700/246	704/9
7	System and method for automatically verifying the performance of a virtual robot	700/264	702/182; 704/9

\* 701/28



	U	1	Document ID	Issue Date	Pages
1	X		US 20020156551 A1	20021024	38
2	X		US 6629087 B1	20030930	37
3	X		US 6615111 B2	20030902	38
4	X		US 6604090 B1	20030805	49
5	X		US 6532401 B2	20030311	38
6	X		US 6363301 B1	20020326	41
7	X		US 6259969 B1	20010710	40